a rotation angle of the three axes is edited as required. In this embodiment, when the gimbal attitude editing module **50** edits attitude information of the gimbal at one node, the gimbal acts according to the edited rotation parameter of the gimbal from that node to the next node. It can be understood that, in other embodiments, it is also feasible that, when the gimbal attitude editing module **50** edits attitude information of the gimbal at one node, the gimbal acts according to the edited rotation parameter of the gimbal for the whole flight route. The gimbal attitude editing module **50** may also edit attitude information of the gimbal respectively at a plurality of nodes at the same time, which is not limited to this embodiment.

[0077] In other embodiments, the gimbal may also be a single-axis or two-axis gimbal.

[0078] The shooting parameter editing module **60** is used for editing the shooting parameter of the imaging device. The shooting parameter includes the size of the aperture, the size of the shutter and the like. In this embodiment, when the shooting parameter editing module **60** edits the shooting parameter of the imaging device at one node, the imaging device shoots according to the edited shooting parameter from that node to the next node. It can be understood that, in other embodiments, it is also feasible that, when the shooting parameter editing module **60** edits the shooting parameter of the imaging device at one node, the imaging device shoots according to the edited shooting parameter for the whole flight route.

[0079] The transmission module **70** is used for transmitting the new flight trajectory edited by the flight trajectory editing module **30**, the attitude information of the unmanned aerial vehicle edited by the unmanned aerial vehicle attitude editing module **40**, the attitude information of the imaging device edited by the gimbal attitude editing module **50**, and the shooting parameter of the imaging device edited by the shooting parameter editing module **60** to the unmanned aerial vehicle to cause the unmanned aerial vehicle to fly according to the new flight trajectory and each axis of the gimbal to rotate according to the edited rotation angle.

[0080] The heading generation method and system of an unmanned aerial vehicle can replace manual real-time precise control over the aircraft at a shooting site to greatly shorten the time of man-made flight operation and avoid influences of human factors on the quality of aerial photography. And at the same time, the heading generation method and system of an unmanned aerial vehicle can avoid the blindness caused by setting waypoints on the map, thus guaranteeing the optimal shooting angle and distance and ensuring that the aircraft and its onboard apparatus can rapidly and efficiently complete high-quality aerial photography assignments.

[0081] In the several embodiments provided in the present invention, it should be understood that the disclosed system, device and method may be implemented in another manner. The described device embodiments above are only schematic. For example, division of the module or unit is merely division of a logical function, and division in another manner may exist in actual implementation. For example, a plurality of units or components may be combined or integrated into another system, or some features may be ignored or not performed. In addition, the mutual coupling or direct coupling or communication connections displayed or discussed may be implemented by using some interfaces, and the indirect coupling or communication connections between the devices or units may be implemented electrically, mechanically or in another form.

[0082] The units described as separate parts may be or may not be physically separate, and parts displayed as units may be or may not be physical units, may be located in one position, or may be distributed on a plurality of network units. Some or all of the units may be selected according to actual needs to achieve the objectives of the solutions of the embodiments.

[0083] In addition, functional units in the embodiments of the present invention may be integrated into one processing unit, or each of the units may exist alone physically, or two or more units are integrated into one unit. The integrated unit may be implemented in a form of hardware, or may be implemented in a form of a software functional unit.

[0084] When the integrated unit is implemented in the form of a software functional unit and sold or used as an independent product, the integrated unit may be stored in a computer-readable storage medium. Based on such an understanding, the technical solutions of the present invention essentially, or the part that makes contributions to the prior art, or all or a part of the technical solutions may be embodied in a form of a software product. The computer software product is stored in a storage medium, and includes several instructions for instructing a computer device (which may be a personal computer, a server, or a network device) or a processor to perform all or a part of the steps of the methods described in the embodiments of the present invention. The foregoing storage medium includes: any medium that can store a program code, such as a USB flash drive, a removable hard disk, a Read-Only Memory (ROM), a Random Access Memory (RAM), a magnetic disk, or an optical disc.

[0085] The above descriptions are merely embodiments of the present invention, but are not intended to limit the patent scope of the present invention. Any equivalent structure or equivalent process variation made by using contents of the specification and the drawings of the present invention, or directly or indirectly applied to other related technical fields, should be likewise included in the patent protection scope of the present invention.

1. A heading generation method of an unmanned aerial vehicle, comprising the following steps of:

making a preliminary flight for selecting a point of view to receive and record flight waypoints of the unmanned aerial vehicle, the waypoints comprising positioning data and flight altitude information of the unmanned aerial vehicle;

generating a flight trajectory according to waypoints of the preliminary flight;

editing the flight trajectory to obtain a new flight trajectory; and

transmitting the edited new flight trajectory to the unmanned aerial vehicle to cause the unmanned aerial vehicle to fly according to the new flight trajectory.

2. The heading generation method according to claim **1**, further comprising:

editing attitude information of an imaging device, and transmitting the edited attitude information of the imaging device to the unmanned aerial vehicle to cause the imaging device to take a photograph according to an edited attitude.

3. The heading generation method according to claim **2**, wherein the unmanned aerial vehicle is provided thereon